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BOX PATENT APPLICATION

Re: Title: DUAL CONCENTRIC ROBOTIC HIGH PERFORMANCE AUTOMATED
TAPE CARTRIDGE SYSTEM

Applicants: James L. Apple, et al.

Filing Date: November 29, 1999

Sir:

Transmitted herewith for filing is the patent application of:

Inventor(s): James L. Apple, et al.
For: DUAL CONCENTRIC ROBOTIC HIGH PERFORMANCE AUTOMATED TAPE
CARTRIDGE SYSTEM

Enclosed are:

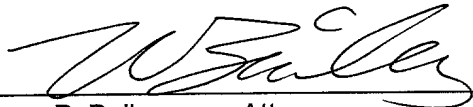
1. [X] Specification (19 pages) and Claims (6 pages).
2. [X] Abstract (1 page)
3. [X] Request to Charge Fee to Deposit Account
4. [X] Twelve (12) sheets of informal drawings.
5. [X] An Assignment of the invention to: Storage Technology Corporation
with Recordation Form Cover Sheet
6. [X] Declaration and Power of Attorney.
7. [X] Information Disclosure Statement.
8. [X] Acknowledgment of Receipt Card.

CLAIMS AS FILED				
FOR	NUMBER FILED	NUMBER EXTRA	RATE	BASIC FEE
				\$760.00
Total Claims	21 - 20	1	x \$18.00	\$ 18.00
Independent Claims	5 - 3	2	x \$78.00	\$156.00
Assignment Recording Fee				\$ 40.00
TOTAL FEE:				\$974.00

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 Nov 29, 1999
 Date

**DUAL CONCENTRIC ROBOTIC HIGH PERFORMANCE AUTOMATED TAPE
CARTRIDGE SYSTEM**

5

BACKGROUND OF THE INVENTION

1. Technical Field:

The present invention relates generally to
10 electronic media storage and retrieval and in particular
to an improved method and apparatus for restoring and
retrieving large amounts of data contained within tape
cartridges.

15 **2. Description of Related Art:**

Storage library systems are capable of storing and
rapidly retrieving large quantities of information stored
in storage media cartridges. Such storage library
systems often use robotic mechanisms to improve the speed
20 of information retrieval and reliability of maintaining
the storage library cartridge inventory.

An automatic cartridge library is a system used for
handling large amounts of information in a data
processing system. These types of systems store and
25 manage large numbers of standardized cassettes containing
magnetic tape on which data is recorded. Typically, an
automated cartridge library is comprised of arrays of
uniquely identified cells in which each cell contains a
single tape cartridge. These cells are arranged in
30 arrays or racks for holding many of these cartridges.

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Each cartridge has identifying information, such as a bar code. A robotic arm, having an optical system for selecting the correct cartridge, is operable within the automated cartridge library to locate a particular cell, retrieve a tape cartridge from the cell, convey the tape cartridge to a tape drive, and insert the tape cartridge into a tape drive.

In many applications, the amount of data is large enough that multiple library storage modules are employed in which each module contains cell arrays and a robotic arm, but does not require additional host computers and does not contain a tape drive. These multiple library storage units are typically arranged adjacent to one another and pass-through ports are provided for passing tape cartridges from one library storage module to an adjacent library storage module. In these systems, a problem exists in automated library systems to facilitate loading and unloading of cartridges when the number of cartridges and drive devices are greater than some threshold of reasonable performance. As a result, a bottleneck is created because the robotic arm within a library module is unable to keep up the requests from a host. For example, exchange rates of over 1,000 tape cartridges per hour strains presently available cartridge tape library systems.

Therefore, it would be advantageous to have an approved method and apparatus for an automated tape cartridge library system having higher performance and better reliability.

BRIEF DESCRIPTION OF THE DRAWINGS

The novel features believed characteristic of the
5 invention are set forth in the appended claims. The
invention itself, however, as well as a preferred mode of
use, further objectives and advantages thereof, will best
be understood by reference to the following detailed
description of an illustrative embodiment when read in
10 conjunction with the accompanying drawings, wherein:

Figure 1 shows an automated cartridge system (ACS)
100 according to one embodiment of the present invention;

Figure 2 shows the interface between the host
computers and the LSMs;

15 **Figure 3** shows an LSM in greater detail;

Figure 4 shows a cross-sectional view of an
automated memory cartridge system **400** according to the
present invention;

Figures 5A-5B show perspective views of a robot
20 suitable for use as robot **110** or robot **150** in **Figure 4**;

Figure 6 shows a block diagram of the robot control
system in accordance with the present invention;

Figures 7-12 shows alternate configurations of the
dual concentric robots **410** and **450** in accordance with the
25 present invention;

Figure 13 illustrates a concentric robots having
redundant arms in accordance with the present invention;

Figure 14 illustrates an alternate embodiment in
which there are four concentric independently rotatable

DETAILED DESCRIPTION OF THE PREFERRED EMBODIMENT

With reference now to the figures, wherein like
5 characters designate like or corresponding parts
throughout the several views, there is shown in **Figure 1**
an automated cartridge system (ACS) **100** in which a
preferred embodiment of the present invention may be
implemented. The ACS **100** is designed to operate with an
10 IBM, or IBM-compatible host computer **102** capable of
communication with a conventional 327X-type terminal
controller **104** as will be described in further detail
herein below. Comprised generally of a library
management unit (LMU) **106** and a library storage module
15 (LSM) **108**, the ACS **100**, through its associated host
software component (HSC) **110**, enables storage and
retrieval of magnetic tape cartridges for use by the host
computer **102** across a conventional channel **112**.

Each LMU **106** serves as the library controller and
20 provides the interface between from one to sixteen host
computers **102** and up to 16 LSMs **108**, as shown in **Figure**
2.

Turning now to **Figure 2**, a block diagram of a
distributed data processing system is depicted in
25 accordance with a preferred embodiment of the present
invention. LMU **106** thus acts as an outboard controller
and interprets commands from host computers **102**, relaying
appropriate instructions to LSM **108** via a control path
(shown in solid lines) and a library control unit (LCU)
30 **109**. On the other and, the read/write data path (dashed

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lines) comes directly from the host computer **102**, through a tape control unit **111** to the tape transports **150** as will be described further herein below, thereby separating control signals from data signals.

5 Each LSM **108** provides the necessary mechanisms for automated cartridge handling. It not only provides the storage area for magnetic tape cartridges utilized in the system, but also includes an optical system for identifying the correct cartridge, a servo-controlled,
10 electromechanical means of selecting the proper cartridge and delivering it to the correct tape drive, and a suitable housing to ensure operator safety and data security.

As shown in greater detail in **Figure 3**, a diagram of
15 a LSM is shown in which the present invention may be implemented. LSM **108** is comprised generally of an outer housing **113** which includes a plurality of wall segments **114** attached to floor plates (not shown) and disposed about a vertical axis **A**. A cylindrical array **134** of
20 storage cells **132** is concentrically arranged about axis **A**, mounted upon the wall segments **114** of the outer housing **113**. A clearance door **138** allows for access into the interior of LSM **108**. The robotics that manipulate the cartridges within LSM **108** are not depicted in **Figure**
25 **3**.

Turning now to **Figure 4**, a cross-sectional view of a library storage module is depicted in accordance with a preferred embodiment of the present invention. Library storage module (LSM) **400** may be implemented as LSM **108** in
30 **Figure 1**. Automated memory cartridge system **400** includes

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two robots **410** and **450**. Robot **410** is mounted to floor
402 of automated memory cartridge system **400** by way of a
number of bolts (not shown) through support **412**. Robot
450 is mounted to the ceiling **404** of automated cartridge
5 system **400** by way of a number of bolts (not shown)
through support **452**. Both robot **410** and robot **450** share
the same theta axis **406** of rotation (i.e., dual
concentric robots). Each robot, robot **410** and robot **450**
operates within a cylindrical or polygonal library **490**
10 containing a plurality of cartridge arrays **492** arranged
cylindrically or in a polygonal shape. A major axis is
an axis within a polygonal array such as cartridge arrays
492. The major axis is usually, but not always,
centrally located within the polygonal array.
15 Furthermore, robot **410** and robot **450** are capable of
rotating about center axis **406** approximately two full
turns before encountering a mechanical stop. This
rotation is a "theta" movement. Collision avoidance is
provided by software control, such as robotic control
20 system **600** described below, which control and monitors
activities of robot **410** and robot **450** and will limit
travel of robot **410** and robot **450** to a location just
short of the mechanical stops.

Robot **410**, in addition to support **412**, also includes
25 a theta drive **414**, an arm **416**, a Z-channel **418**, a Z-
transport **420**, a Z-motor (not shown), and a hand **422**.
Similarly, robot **450**, in addition to its support **452**,
also includes a theta drive **454**, an arm **456**, a Z-channel
458, a Z-transport **460**, a Z-motor (not shown), and a hand
30 **462**. The purpose of the Z transport mechanism is to

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provide a means of moving the hand **422** and **462** in a vertical direction. Theta Drive **414** is attached to support **412** and includes a motor that turns an arm **416** about axis **406**. Similarly, theta drive **454** is attached to support **452** and includes a motor that turns an arm **458** about axis **406**.

Hands **422** and **462** provide the actual handling of the cartridges (not shown). Each hand, hand **422** and hand **462**, is attached to a transport that can be moved up and down on its respective Z-channel **418** and **458** (Z move). Each hand, hand **422** and hand **462**, is capable of reaching out, gripping a cartridge, and pulling the cartridge out of its storage cell. Hands **422** and **462** can then be moved to another location through a combination of theta and Z moves and placed in another cell, a tape drive, or some other device located within the LSM **400**.

Robot **410** and robot **450** are essentially identical with minor differences in the way certain parts are assembled to provide proper orientation for the upper and lower hand assemblies. Robots and LSMs such as those described herein may be obtained from Storage Tek with such modifications as to achieve the apparatus of the present invention. Perspective views of a robot suitable for use as robot **410** or robot **450** are shown in **Figures 5A** and **5B**. **Figure 5A** shows the robot from an orientation 180 degrees removed from the orientation shown in **Figure 5B**.

More details about the construction and operation of the robots **410**, **450** and hands **422**, **462** as well as other features of automatic storage and retrieval systems may

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be found in U.S. Patent No. 4,932,826 issued to Moy, et al. which is incorporated herein by reference.

Each robot, robot **410** and robot **450**, has an absolute position detection device that receives power from the opposite robot's supply. This potentially low-resolution device need not be the primary feedback element for rotational position control. The detected absolute position is made available to both robot **410** and robot **450**. The primary purpose of the absolute position devices is collision avoidance during full speed operation of both robots **410** and **450**. The sensors enable both robots **410** and **450** to operate simultaneously at full speed thus almost doubling performance of the library **490**. However, if one robot **410** or robot **450** is rendered disabled, the first mode of collision avoidance is for that robot to be commanded to move clear of the functioning robot's path. In the event that the disabled robot cannot evade potential collision with the remaining functional robot, use is made of the absolute position detection by the active robot. Any action that is not obstructed by the disabled robot is completed at full performance speeds. An action that is obstructed by the disabled robot is carried out at full speed until the vicinity of the disabled robot is reached. The disabled robot is then pushed to a safe area by the active robot at reduced speeds. The absolute position devices are used secondarily during initialization for determining orientation of the two robots.

Turning now to **Figure 6**, there is shown a block diagram of the robot control system **600** in accordance

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with the present invention. The presence of the two robots **410** and **450** not only provides for high performance but also establishes redundant hardware for improve reliability. Along with the redundant robotics are
5 redundant electronics and power. The main electronics (robot controllers) **602**, **612** and processors **604**, **606**, **614**, and **616** have crossover capability so that in the event of failure of one, the other can operate both robots **410**, **450**. The system **600** also contains two power
10 supplies with dual line cords so power to the library can come from two different building circuits. Cards are hot pluggable to provide maximum up time in the event of failure. In addition to redundant hardware, code updates may be loaded without interrupting operation of the
15 library.

Two digital signal processing (DSP) processors are used to control each robot, one is on the controller and one is on the hand. Processors **606** and **608** control robot hand **422** while processors **616** and **618** control robot hand
20 **462**. Processors **608** and **618** are hand processors used in conjunction with the vision system used to decode cartridge labels, and hand position as determined from targets on the storage arrays. Also, processors **608** and **618** are used to control the reach and grip functions of
25 the hand. A second DSP processor resides within the library control unit (LCU) electronics for each robot. Processors **606** and **616** control the theta and Z robot axes as well as providing direct communications to the hand DSP processors **608** and **618**. Both sets of DSP processors
30 are optimized to run in a real-time environment.

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A host interface processor (HIP) **604**, **614** provides the interface between the external control environment for host **620** and host **630** and the LCU DSP processors **606** and **616**. The HIP operation environment is multitasking and the two HIPs **606** and **616** provide fail-over capability.

Returning now to **Figure 4**, in addition to twin robots **410** and **450**, library **400** contains mechanisms to facilitate insertion and removal of cartridges by the operator. This operation is accomplished through the use of a cartridge access port (CAP) which provides the convenience of loading and unloading through the use of cartridge magazines. The library storage module also has the ability to pass and receive cartridges between other libraries through the use of a cartridge exchange mechanism.

Thus, the present invention utilizing dual concentric robots is able to provide exchange rates of over 1,000 per hour. Each of the two robots has access to the same media and the access is essentially non-reliant on the second robot's activities. Furthermore, access to all drives in the system is equally shared by both robots to the greatest extent possible.

Turning now to **Figures 7-12**, alternate configurations of dual concentric robot **410** and robot **450** are illustrated in accordance with the present invention. For clarity, the library storage module, robotic hands, and other details are not shown in these views.

In **Figure 7** a cross sectional view of dual concentric robots with one robot mounted to the ceiling

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and one to the floor with fixed motors is illustrated in accordance a preferred embodiment of the present invention. A support **702** is mounted to floor **704** of the library storage module and a column **706** is attached to support **702**. A sleeve **708** fits and turns around bearings **710** in column **706**. A motor **712** is attached to column **706** and turns a belt (not shown) which in turn, rotates sleeve **708**. Sleeve **708** is attached to arm **714** which is in turn attached to Z-channel **716**. The rotation of sleeve **708** causes the Z-channel **716** to rotate. A second support **720** is attached to the ceiling **722** of library storage module and a second column **724** is attached to second support **720**. A second sleeve **726** fits around second column **724** and rotates on bearings **728** in second column **724**. A second motor **730** is attached to column **724** and turns a belt (not shown) which in turn rotates sleeve **726**. Sleeve **726** is connected to arm **732**, which is, in turn, connected to Z-channel **734**. The rotation of sleeve **726** causes Z-channel **734** to rotate.

In **Figure 8** a cross sectional view of dual concentric robots with one robot mounted to the ceiling and one to the floor with motors mounted to the z-column is illustrated in accordance with a preferred embodiment of the present invention. A support **802** is attached to floor **804** of library storage module and a column **806** is attached to support **802**. A sleeve **808** fits around column **806** and rotates on bearings **810** in column **806**. A motor **812** is attached to sleeve **808** and is also attached to Z-channel **814**. Motor **812** turns a belt (not shown) which loops around column **806** causing motor **812** and, in turn,

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Z-channel **814** to rotate about column **806**. A second support **832** is attached to ceiling **834** of library storage module and a second column **836** is attached to second support **832**. A second sleeve **838** fits around column **806** and rotates on bearings **840** in second column **836**. A second motor **842** is attached to second sleeve **838** and is also attached to Z-channel **844**. Second motor **842** turns a belt (not shown) which loops around second column **836** causing second motor **842** and, in turn, Z-channel **844** to rotate about second column **836**.

In **Figures 9** a cross sectional diagram of dual concentric robots both mounted to the floor with inline motors is illustrated in accordance with a preferred embodiment of the present invention. A support **902** is mounted to floor **904** of the library storage module. The motors driving the theta movements of each arm are placed in-line within column **906** that is attached to support **902**. One motor is mounted above the other motor. The lower motor is comprised of stator **908**, bearings **916**, and a rotor **940**. The upper motor is comprised of stator **910**, bearings **922**, and rotor **930**. The stators **908** and **910** are fixed in position, i.e., attached to support **902** via column **906**. Rotor **930** is attached to arm **918** which is in turn connected to Z-channel **914** and rotates about stator **910**. Rotor **940** is attached to arm **912** which is in turn connected to Z-channel **920** and rotates about stator **916**. Thus, the rotors **930** and **940** allow for theta movement of arms **918** and **912**. Bearings **916** allow rotor **940** to turn around stator **908** and bearings **922** allow rotor **930** to

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turn around stator **910**. The Z-channels **914** and **920** may be attached to robotic hands (not shown).

In **Figure 10** a cross sectional diagram of dual concentric robots both mounted to the floor having
5 external motors is illustrated in accordance with a preferred embodiment of the present invention. A support **1002** is attached to the floor **1004** of the library storage module. An external motor **1006** is attached to a column **1008** to drive the theta movement of arm **1010**. Arm **1010**
10 is attached to a sleeve **1012** which fits around column **1008** and turns over lubricated bearings **1014** in column **1008**. Also attached to arm **1010** is Z-channel **1016** to which the robotic hand (not shown) attaches. A second external motor **1020** is attached to column **1008** above the
15 first motor **1006** to drive the theta movement of arm **1022**. Arm **1022** is attached to a second sleeve **1024**, which fits around column **1008** and turns over lubricated bearings **1026** in column **1008**. Also attached to arm **1022** is Z-channel **1028** to which a robotic hand (not shown) may be
20 attached.

Figure 11, illustrates dual concentric robots with end drives for theta rotation in accordance with a preferred embodiment of the present invention. A support **1102** is attached to the floor **1104** of the library storage
25 module. A motor **1112** is also attached to support **1102**. A rotating member **1108** fits into a slot **1110** in support **1102**, which allows rotating member **1108** to rotate freely about axis **1150**. A motor **1112** is attached to support **1102** and turns a belt (not shown) which, in turn, rotates
30 rotating member **1108** about axis **1150**. Rotating member

1108 is attached to an arm **1114**, which is attached to Z-channel **1116**. The rotation of rotating member **1108** rotates Z-channel **1116**. A second arm **1118** has a slot **1120** which fits over rotating member **1108** and is also
5 attached to Z-channel **1122**. Second arm **1118** provides support to Z-channel **1122** and is able to rotate freely around and independently of rotating member **1108**.

A second support **1132** is attached to ceiling **1134** of the library storage module. A second motor **1136** is also
10 attached to second support **1132**. A second rotating member **1138** fits into a second slot **1140** in second support **1132**, which allows second rotating member **1138** to rotate freely about axis **1150**. A second motor **1142** is attached to second support **1132** and turns a belt (not
15 shown) which, in turn, rotates second rotating member **1138** about axis **1150**. Second rotating member **1138** is attached to an third arm **1144** which is attached to Z-channel **1122**. The rotation of rotating member **1138** rotates Z-channel **1122**. A fourth arm **1148** has a slot
20 **1146** which fits over rotating member **1138** and is also attached to Z-channel **1116**. Fourth arm **1148** provides support to Z-channel **1116** and is able to rotate freely around and independently of rotating member **1138**. Thus independent theta rotation of both Z-channels **1116** and
25 **1122** is achieved.

Figure 12 illustrates dual concentric robots having inner **1202** and outer **1206** drive shafts in accordance with a preferred embodiment of the present invention. An inner drive shaft **1202** has a bearing **1204** at a lower
30 extremity which fits into the floor (not shown) of the

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library storage module. Inner drive shaft **1202** is cylindrically disposed within an outer drive shaft **1206**. The outer drive shaft **1206** is connected to a belt **1208** which is connected to motor **1210** which provides rotation to turn outer drive shaft **1206**. Outer drive shaft **1206** is connected to a lower arm **1212** which is connected to Z-channel **1214**. Z-channel **1214** is connected to robotic hand **1216**.

Inner drive shaft **1202** is connected to a belt **1220** which is connected to motor **1222** that provides rotation to turn inner drive shaft **1202**. Inner drive shaft **1202** is connected to an upper arm **1224** that is connected to Z-channel **1226**. Z-channel **1226** is connected to a robotic hand **1228**. Rotation of the inner drive shaft **1202** provides rotation of robotic hand **1228** within the library storage module. At an upper extremity of inner drive shaft **1202** is a second bearing **1230** which connects to the ceiling (not shown) of the library storage module, thus supporting inner drive shaft **1202**.

Figure 13 illustrates concentric robots having redundant arms in accordance with a preferred embodiment of the present invention. A lower arm **1302** supporting two Z-channels **1304** and **1306** rotates about an axis **1308** within library storage module **1310**. An upper arm **1312** is situated above lower arm **1302** to rotate about axis **1308** as well. Attached to upper arm **1312** are two Z-channels **1314** and **1316**. Lower arm **1302** extends radially out from axis **1308** farther than does upper arm **1312**. Thus, each arm, arm **1302** and arm **1312** may move independently of each other without the respective pair of Z-channels **1304**,

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1306, 1314, and 1316 of each arm, arm 1302 and arm 1312, colliding. Robotic hands (not shown) may be used on each pair of Z-channels 1304, 1306, 1314, and 1316. The robotic hands mounted on the outer Z-channels of Z-channel pairs 1304, 1306, 1314, and 1316 may extend outward as necessary from respective outer Z-channels of Z-channel pairs 1304, 1306, 1314, and 1316 such that each robotic hand may reach and grasp cassettes from the outer library storage module 1310. Robotic hands (not shown) mounted to the inner Z-channels of Z-channel pairs 1304, 1306, 1314, and 1316 service cartridges mounted on inner walls (not shown).

Figure 14 illustrates an alternate embodiment in which four concentric independently rotatable arms are present within a library storage module 1410 in accordance with a preferred embodiment of the present invention.

Figure 15 shows a schematic diagram of four independently rotatable arms with off-centered axes of rotation in accordance with a preferred embodiment of the present invention. Each arm (not shown) are attached to a different rotation point, points 1502, 1504, 1506, and 1508. Each arm consists of a 4410 type cantilever beam arm holding a z-column. The arms are mounted to library floor 1550 off-center such that each arm assembly has its own theta rotation point as shown by rotation points 1502, 1504, 1506, and 1508. These separate rotation points 1502, 1504, 1506, and 1508 enables independent theta movements of multiple robots, although each robot would have its own zone of operation as shown by zones

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1501, 1503, 1505, and 1507. Zones **1501, 1503, 1505, and 1507** are overlapping zones and provide for "pass through". Total redundancy may not be achieved, but more jobs per hour per silo is accomplished. The somewhat
5 elliptical sweep of the robotic hand is counteracted by a variable reach depth, adding size to the hand assembly, or a linkage designed to pivot the hand out further as the arm gets further from the LSM wall.

The description of the present invention has been
10 presented for purposes of illustration and description, but is not intended to be exhaustive or limited to the invention in the form disclosed. Many modifications and variations will be apparent to those of ordinary skill in the art. The embodiment was chosen and described in
15 order to best explain the principles of the invention, the practical application, and to enable others of ordinary skill in the art to understand the invention for various embodiments with various modifications as are suited to the particular use contemplated.

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3 and said second center column is attached at one end to a
4 floor of the library.

1 3. The apparatus of claim 1, wherein each of said hands
2 is moveable longitudinally along a respective one of said
3 arms.

1 4. The apparatus of claim 1, wherein each of said
2 center columns is substantially cylindrically symmetric.

1 5. The apparatus of claim 1, wherein said first center
2 column is axially disposed within said second center
3 column.

1 6. The apparatus of claim 1, wherein the library
2 comprises walls arranged around a central axis and the
3 storage units are stored in cells in the walls.

1 7. The apparatus of claim 1, wherein each of said
2 center columns is substantially cylindrical.

1 8. A data tape storage and retrieval system,
2 comprising:

3 a plurality of storage cells arranged radially
4 around a central point, wherein the plurality of storage
5 cells are configured to receive data storage objects;

6 a first rotational horizontal beam rotatable around
7 the central point;

8 a second rotational horizontal beam rotatable around
9 the central point;

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10 a plurality of vertical supports, one of said
11 vertical supports attached to one end of each of said
12 rotational horizontal beams;
13 a plurality of gripping means configured for
14 gripping data storage objects to be retrieved from said
15 plurality of storage cells; and
16 means for movably attaching at least one of said
17 gripping means to traverse each of said vertical
18 supports; wherein
19 each of said rotational horizontal beams is capable
20 of rotation independent of the rotation of the other of
21 said rotational horizontal beams.

1 9. A data storage and retrieval system comprising:
2 a polygonal array of cells, wherein the polygonal
3 array of cells are inwardly disposed with openings
4 configured to receive data storage units;
5 a first robot unit, located within the polygonal
6 array of cells, wherein the first robot unit transports a
7 data storage unit to and from the polygonal array of
8 cells; and
9 a second robot unit, located within the polygonal
10 array of cells, wherein the second robot unit manipulates
11 data storage units placed in the polygonal array of cells
12 independently of the first robot unit.

1 10. The data storage and retrieval system of claim 9,
2 wherein the data storage units are electronic magnetic
3 storage cartridges.

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1 11. The data storage and retrieval system of claim 9,
2 wherein the polygonal array of cells is a circular array
3 of cells.

1 12. The data storage and retrieval system of claim 9,
2 further comprising:
3 collision avoidance means for preventing collisions
4 between the first robot unit and the second robot unit
5 during operation.

1 13. The data storage and retrieval system of claim 9,
2 wherein the first robot unit and the second robot unit
3 both include a hand, wherein the hand is moveable to
4 remove a data storage unit from a cell from the
5 cylindrical array of cells.

1 14. The data storage and retrieval system of claim 9,
2 wherein the polygonal array of cells in the data storage
3 and retrieval system includes a major axis within the
4 polygonal array of cells, wherein the first robot unit
5 and the second robot unit are located along the major
6 axis.

1 15. An apparatus for retrieval of storage units from a
2 library, the apparatus comprising:
3 a first center column having a first arm with first
4 and second ends wherein the first end of said first arm
5 is attached to said first center column and said first
6 arm extends substantially radially outward from said
7 first center column;

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8 a first hand attached to the second end of said
9 first arm for manipulating storage units from the
10 library;

11 a second center column having a second arm with
12 first and second ends wherein the first end of the second
13 arm is attached to the second center column and said
14 second arm extends substantially radially outward from
15 said second center column; and

16 a second hand attached to the second end of said
17 second arm for manipulating storage units from the
18 library; wherein

19 said first arm and said second arm rotate about a
20 same vertical axis of rotation; and

21 each arm and hand is independently moveable from the
22 other arm and hand.

1 16. The apparatus of claim 15, wherein each of said
2 hands is moveable longitudinally along a respective one
3 of said arms.

1 17. The apparatus of claim 15, wherein each of said
2 center columns is substantially cylindrically symmetric.

1 18. The apparatus of claim 15, wherein said first center
2 column is axially disposed within said second center
3 column.

1 19. The apparatus of claim 15, wherein the library
2 comprises walls arranged around a central axis and
3 storage units are stored in cells in the walls.

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1 20. The apparatus of claim 15, wherein each of said
2 center columns is substantially cylindrical.

1 21. A data tape storage and retrieval system,
2 comprising:
3 a plurality of storage cells arranged radially
4 around a central point;
5 a first rotational horizontal beam rotatable around
6 the central point;
7 a second rotational horizontal beam rotatable around
8 the central point;
9 a plurality of vertical supports, one of said
10 vertical supports attached to one end of each of said
11 rotational horizontal beams;
12 a plurality of gripping means for gripping data
13 storage objects to be retrieved from said plurality of
14 storage cells; and
15 means for movably attaching at least one of said
16 gripping means to traverse each of said vertical
17 supports, wherein each of said rotational horizontal
18 beams is capable of rotation independent of the rotation
19 of the other of said rotational horizontal beams.

ABSTRACT OF THE DISCLOSURE**DUAL CONCENTRIC ROBOTIC HIGH PERFORMANCE AUTOMATED TAPE
CARTRIDGE SYSTEM**

5

A data storage and retrieval system. In a preferred embodiment, the data storage and retrieval system includes a polygonal array of cells that are inwardly disposed with openings configured to receive data storage units. A first robot unit to transport a data storage unit to and from the polygonal array of cells is located within the polygonal array of cells. A second robot unit is also located within the polygonal array of cells to transport a data storage unit to and from the polygonal array of cells. The second robot unit manipulates the data storage units placed in the cylindrical array of cells independently of the first robot unit.

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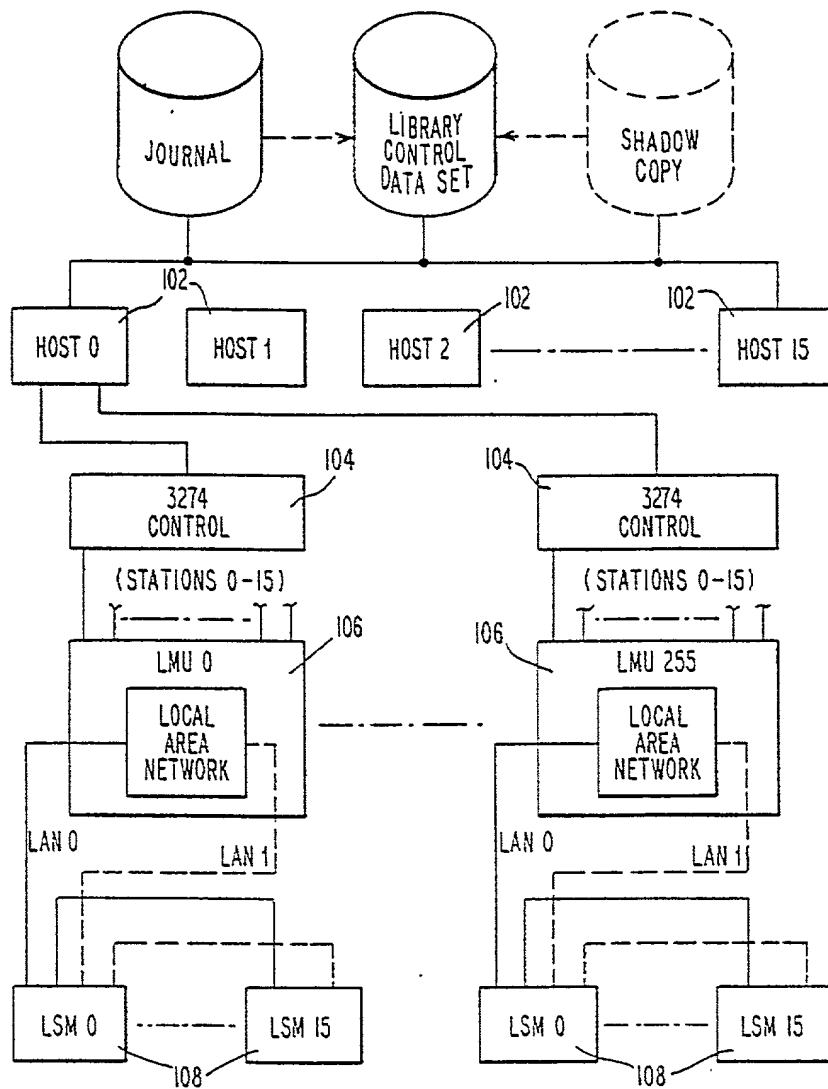


Fig. 2

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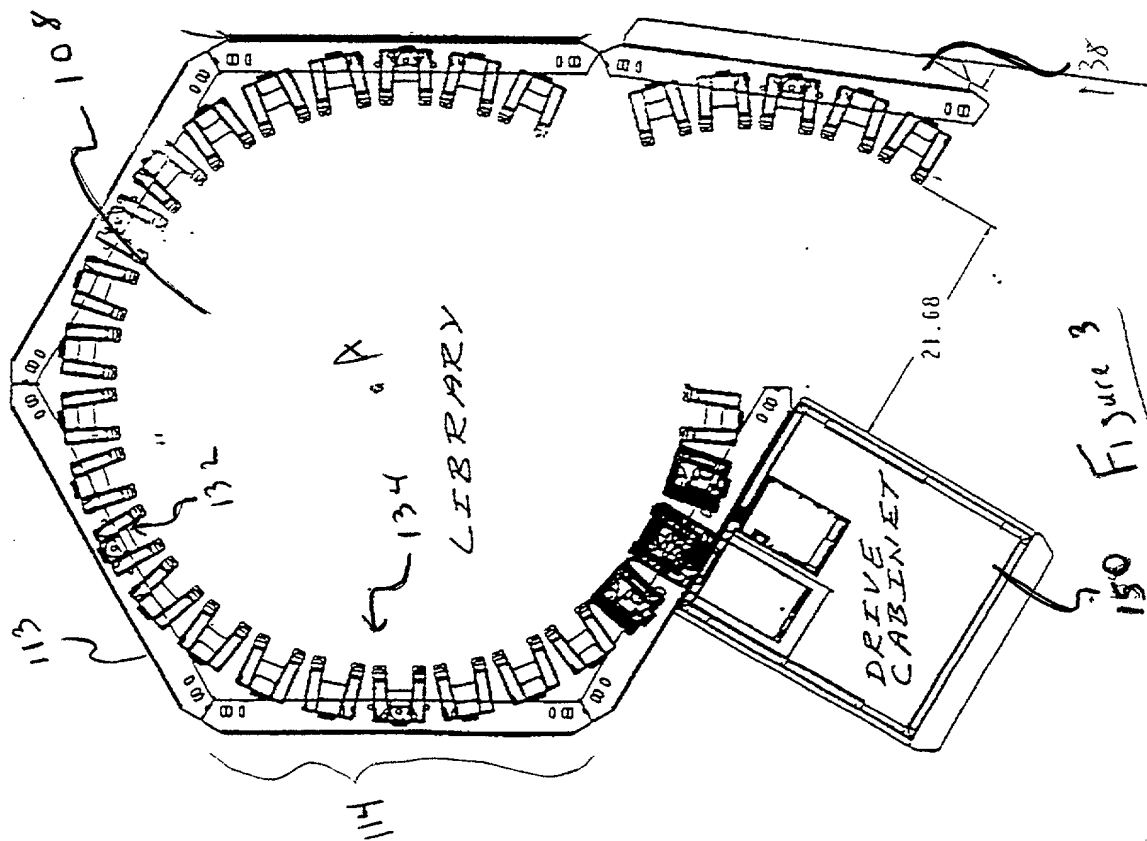


Figure 3

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450 440b 404 452 456 454 490

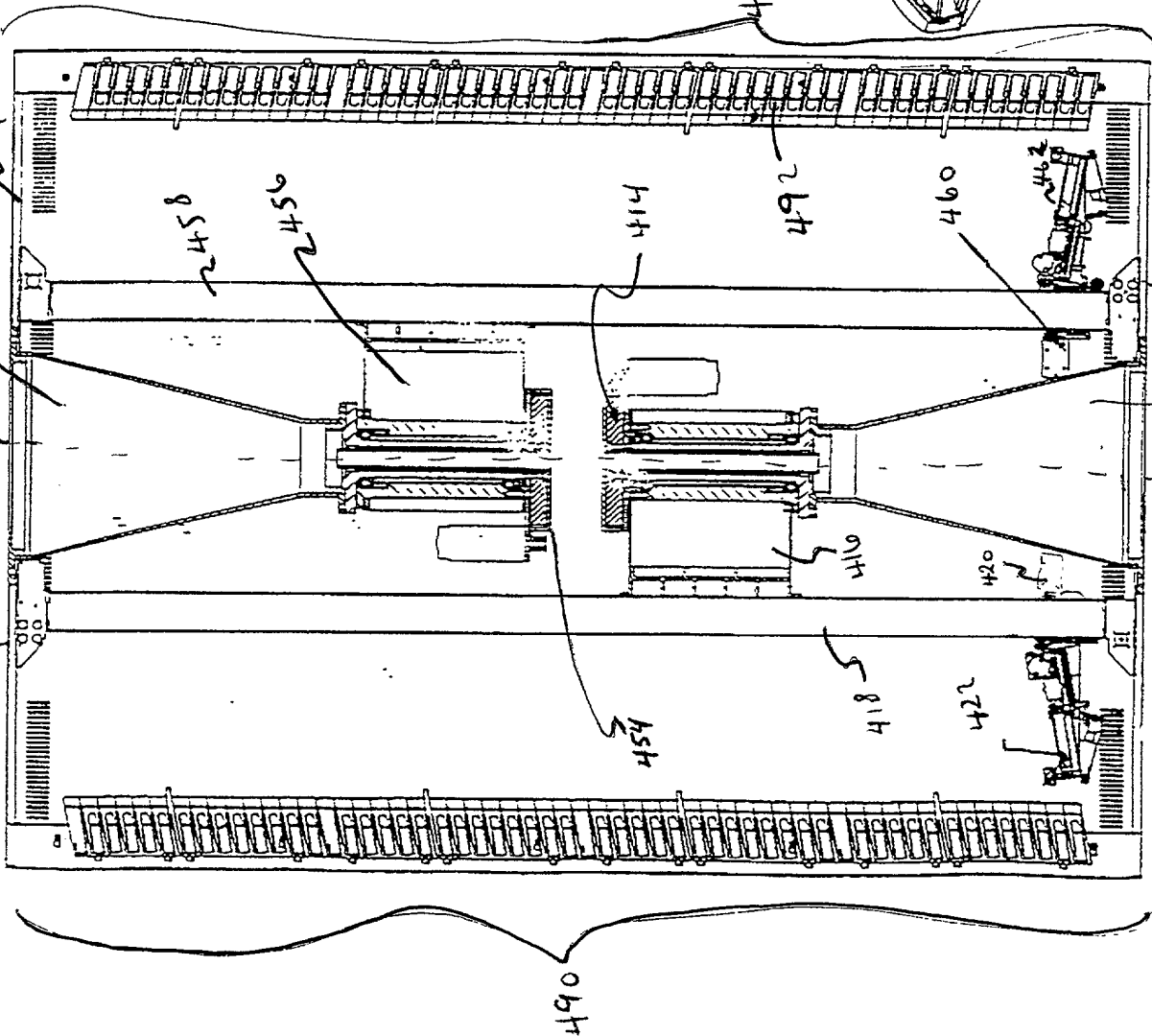


Figure 4

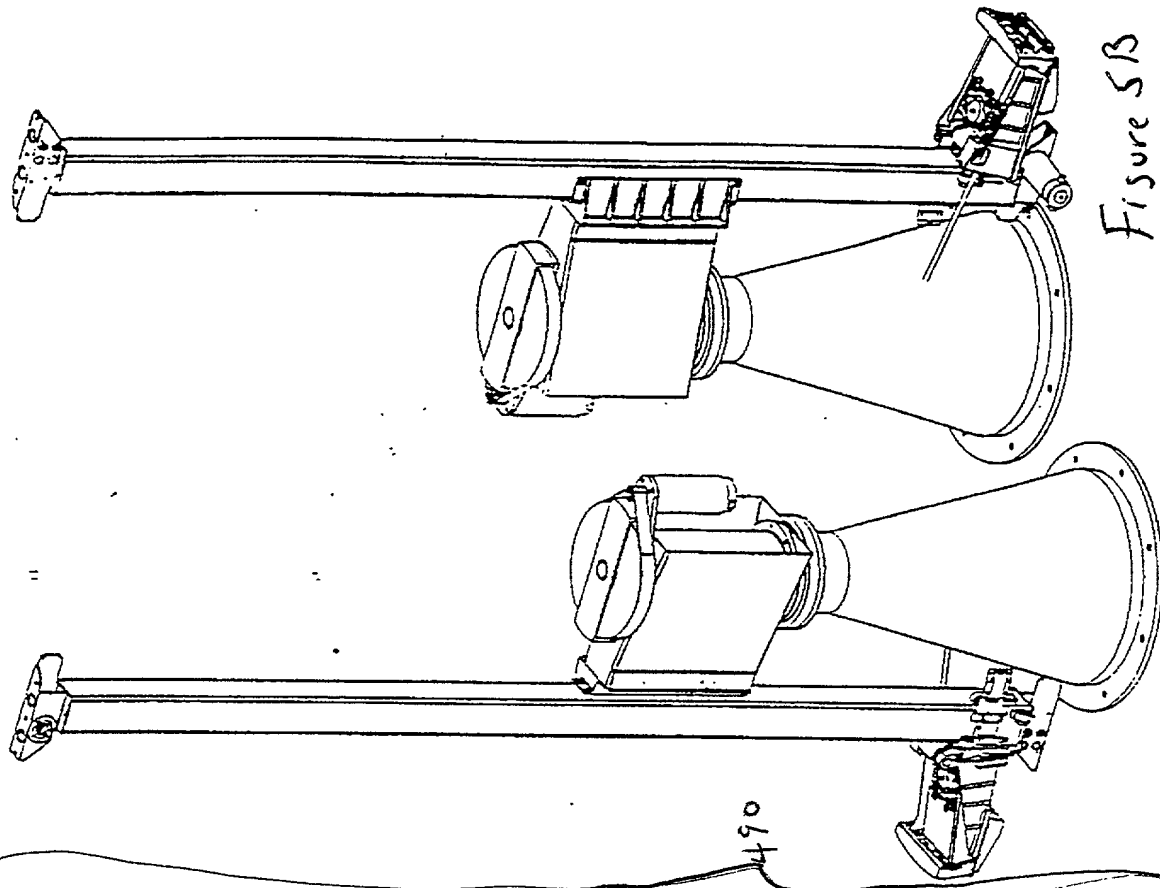


Figure 5A

Figure 5B

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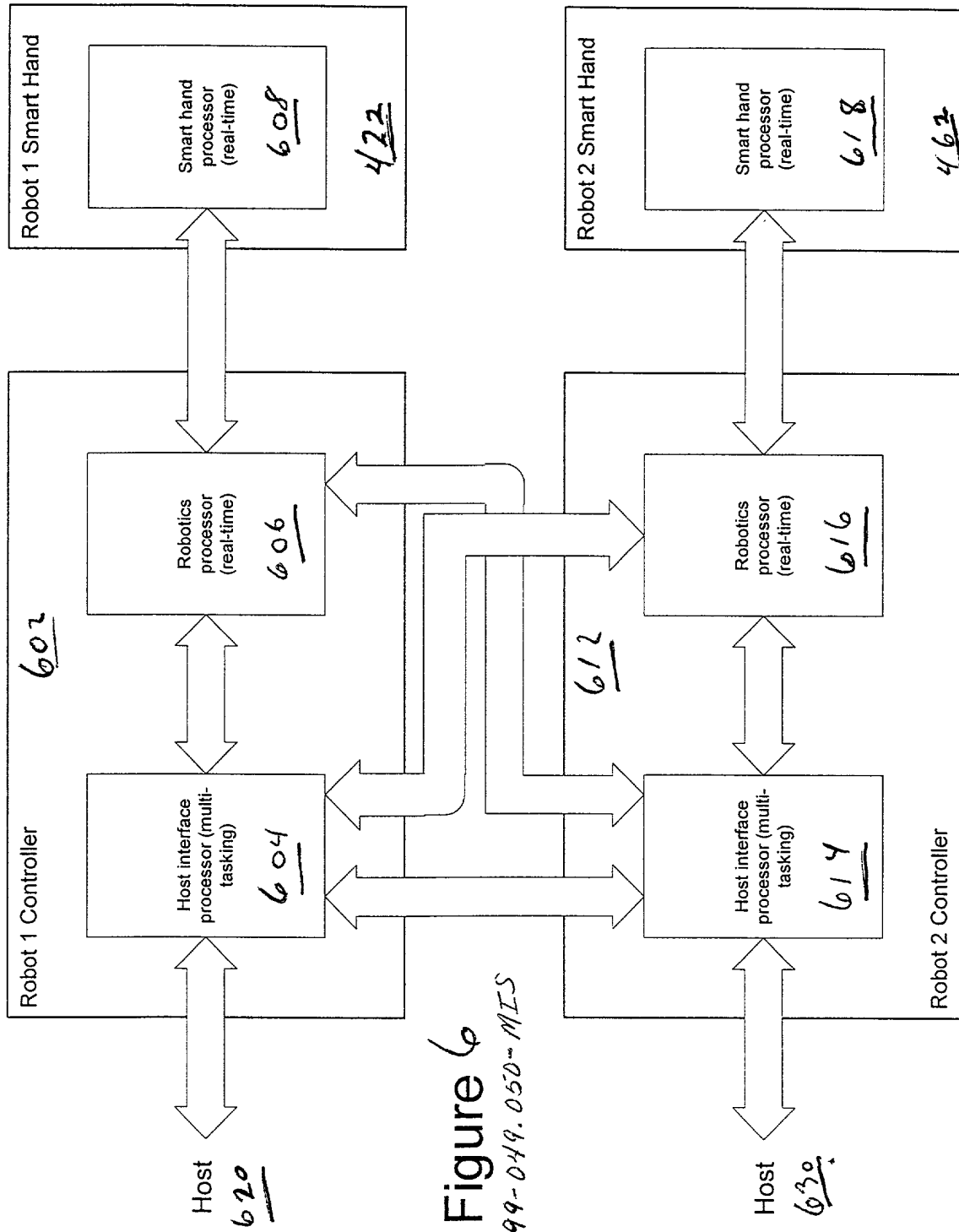


Figure 6
99-0449.050-MIS

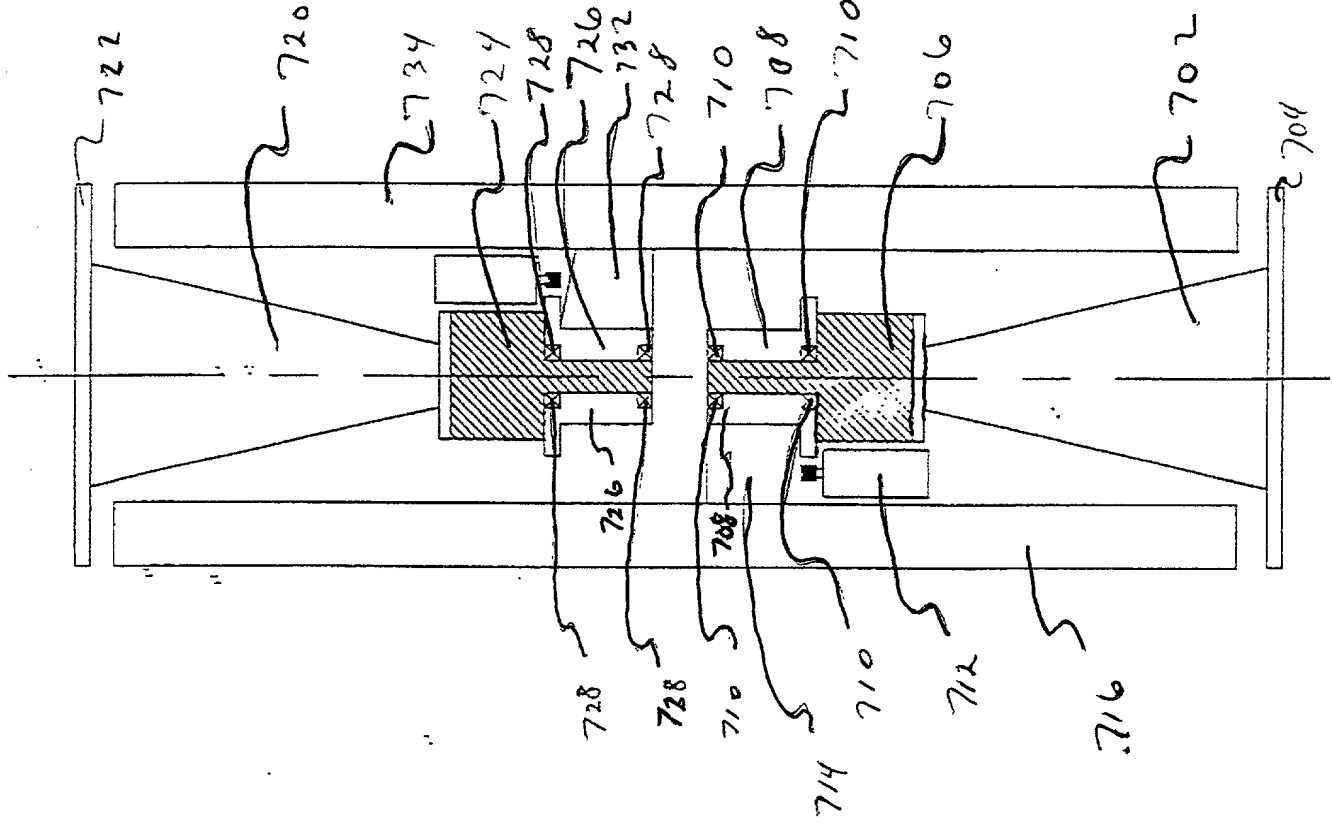


Figure 7

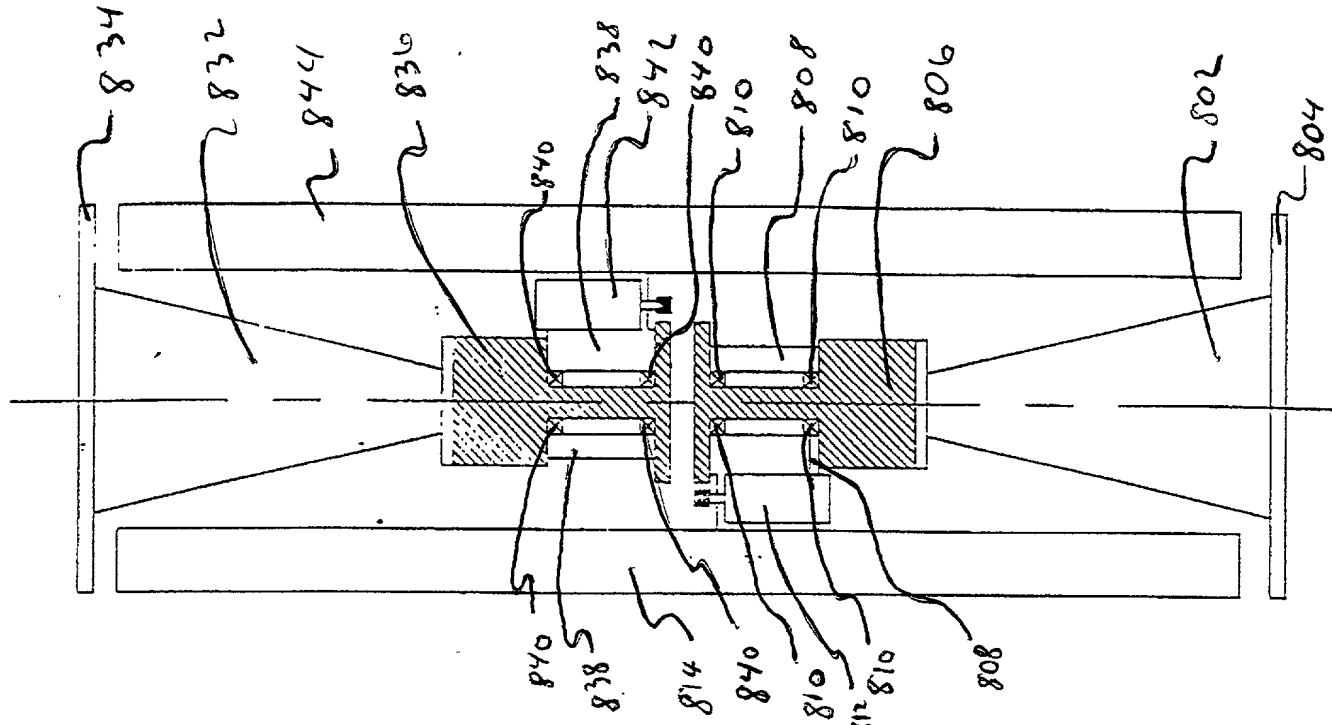


Figure 8

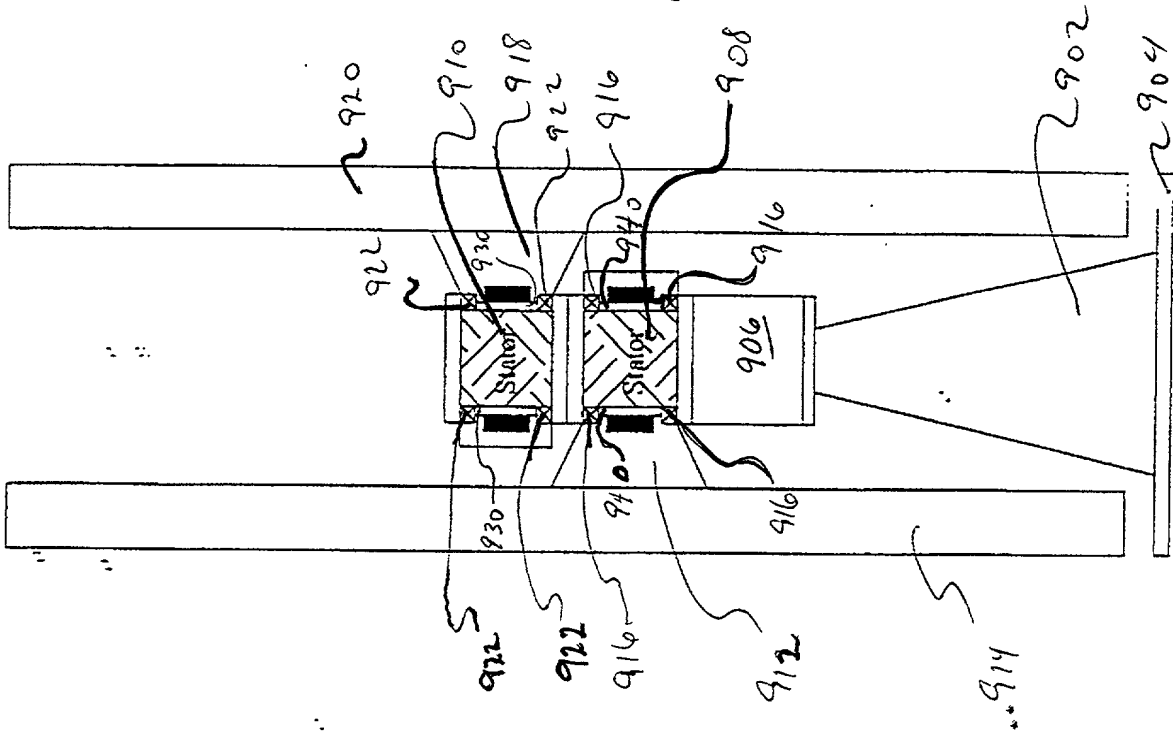


Figure 9

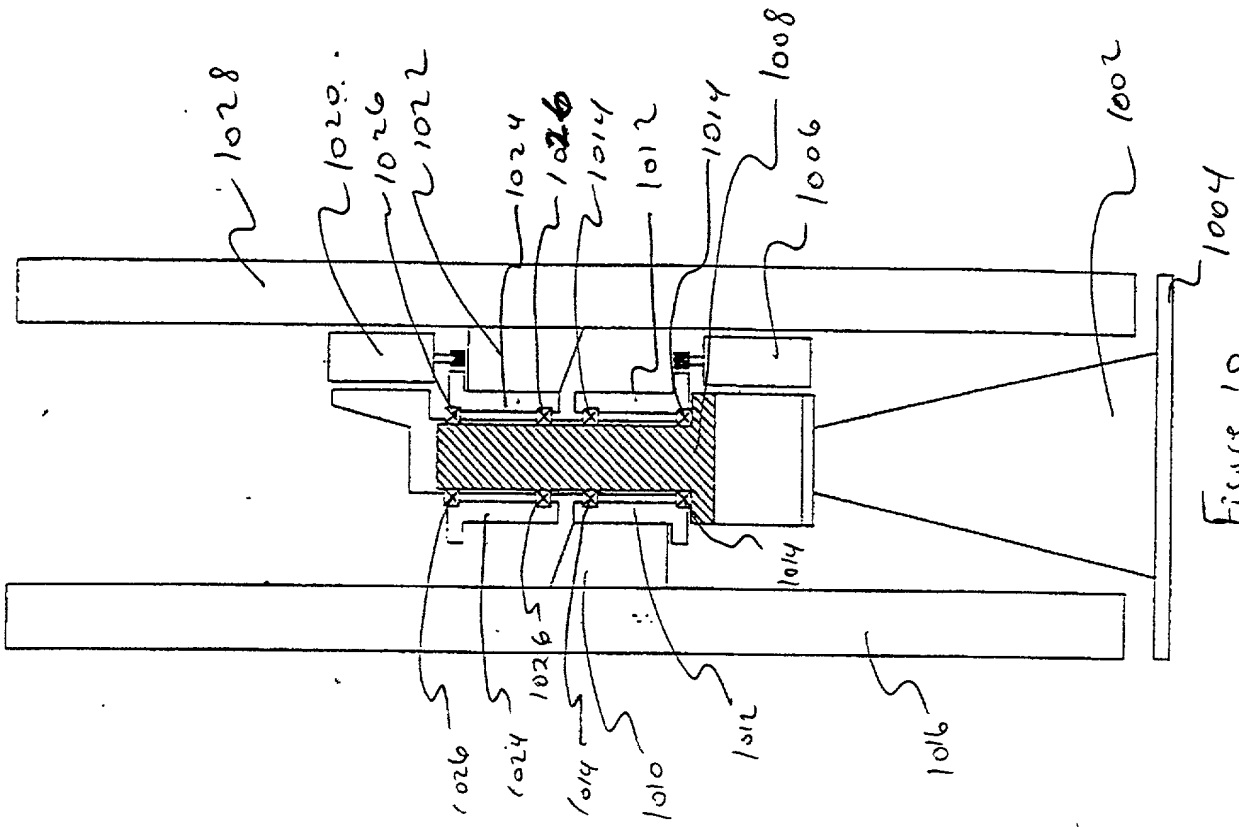


Figure 10

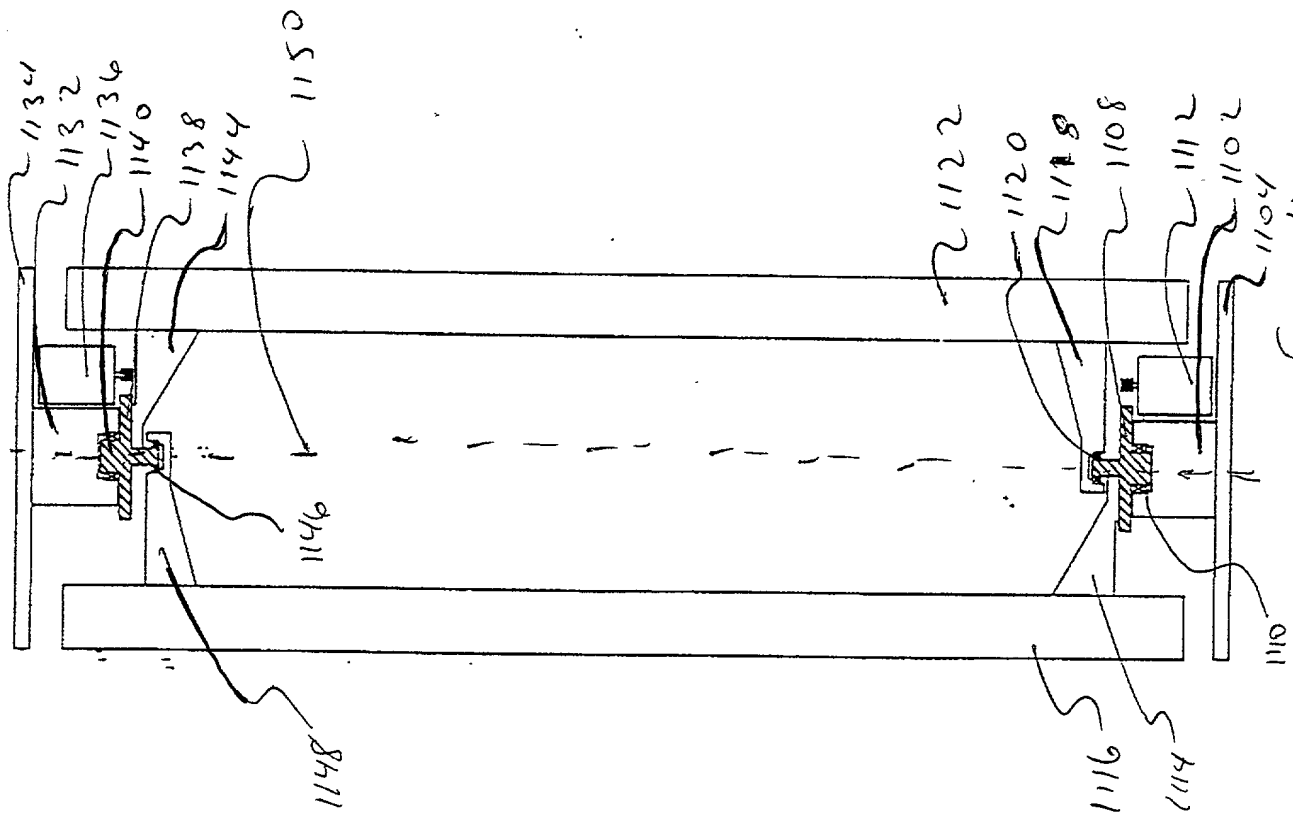


Figure 11

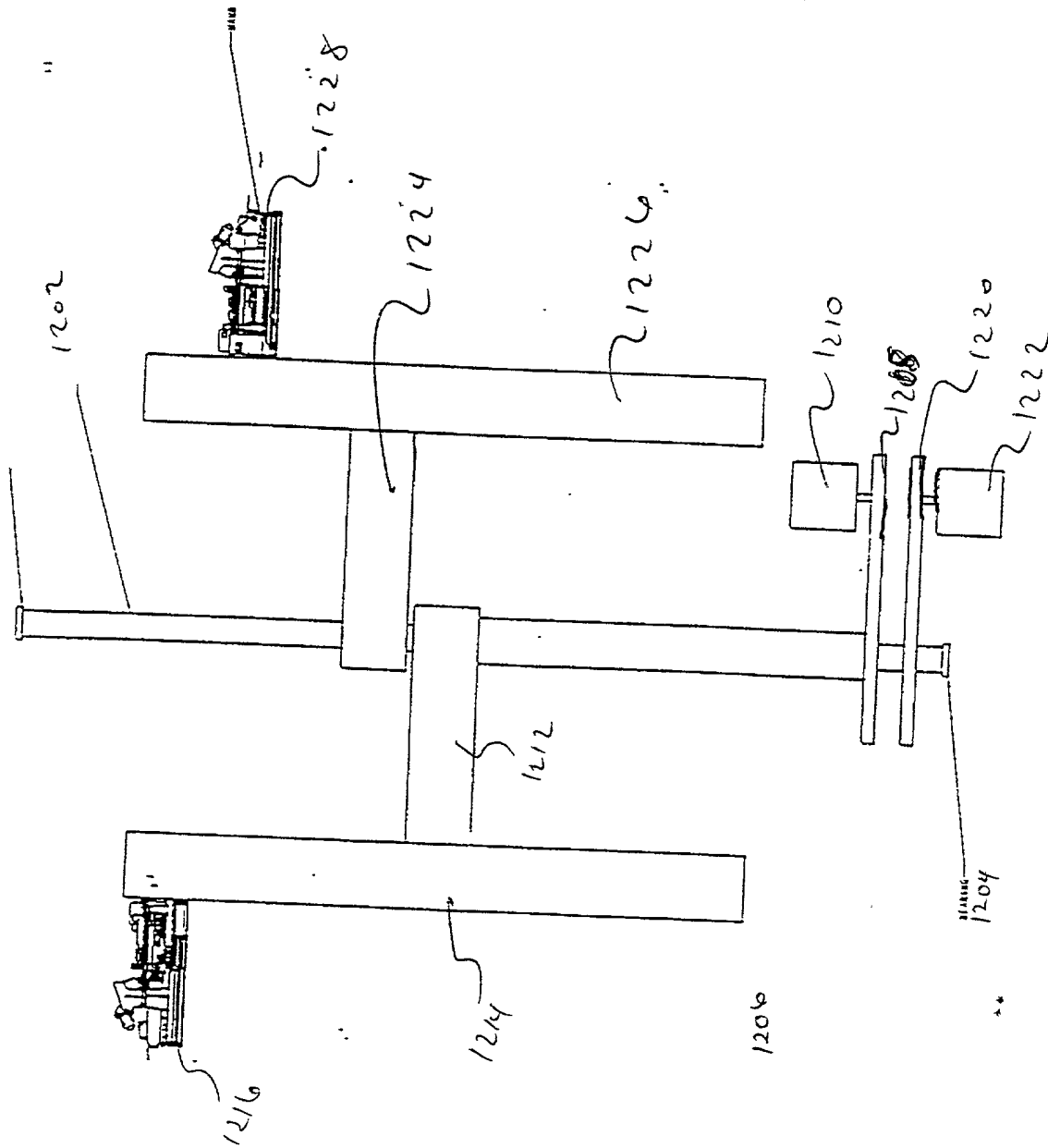


Figure 12

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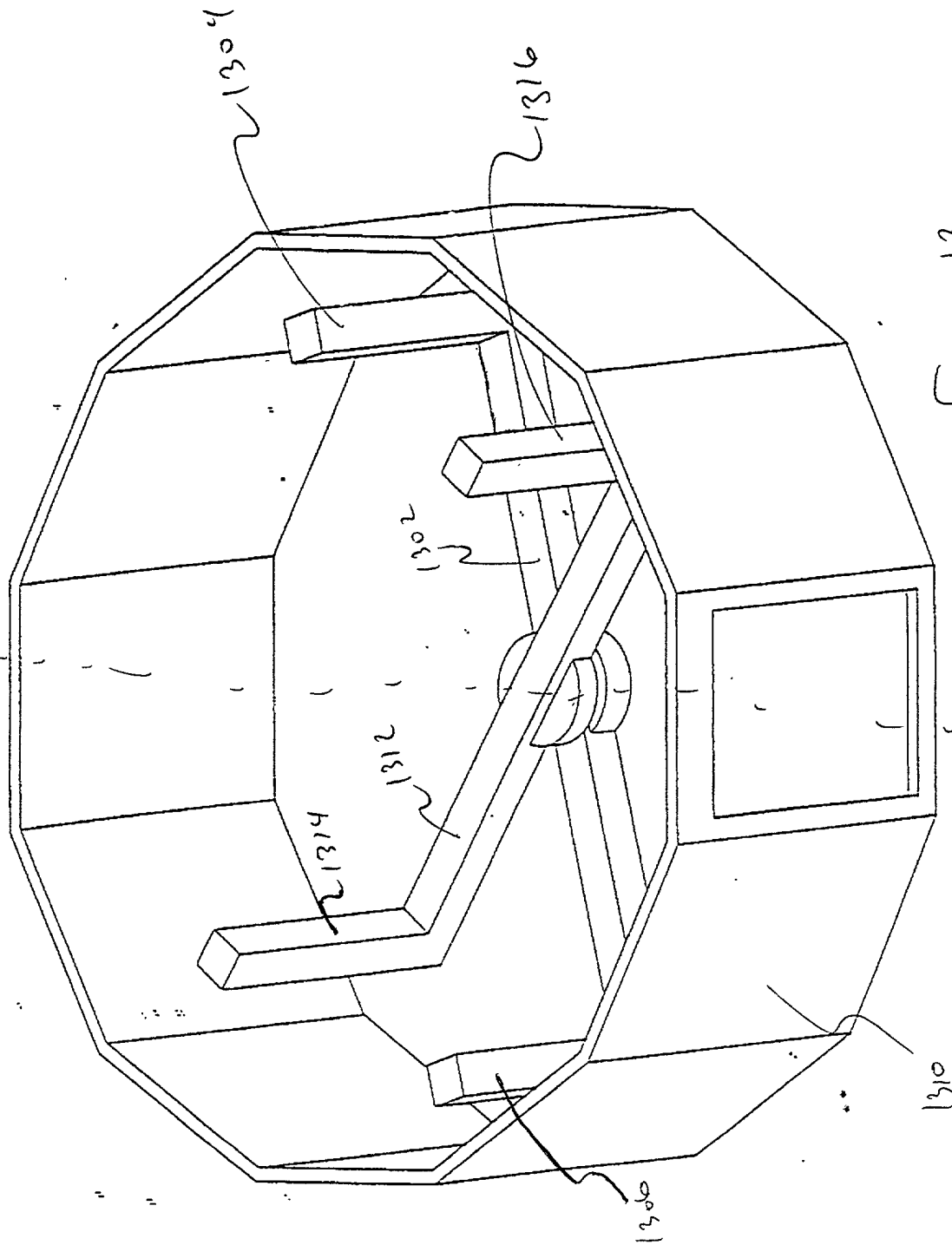


Figure 13

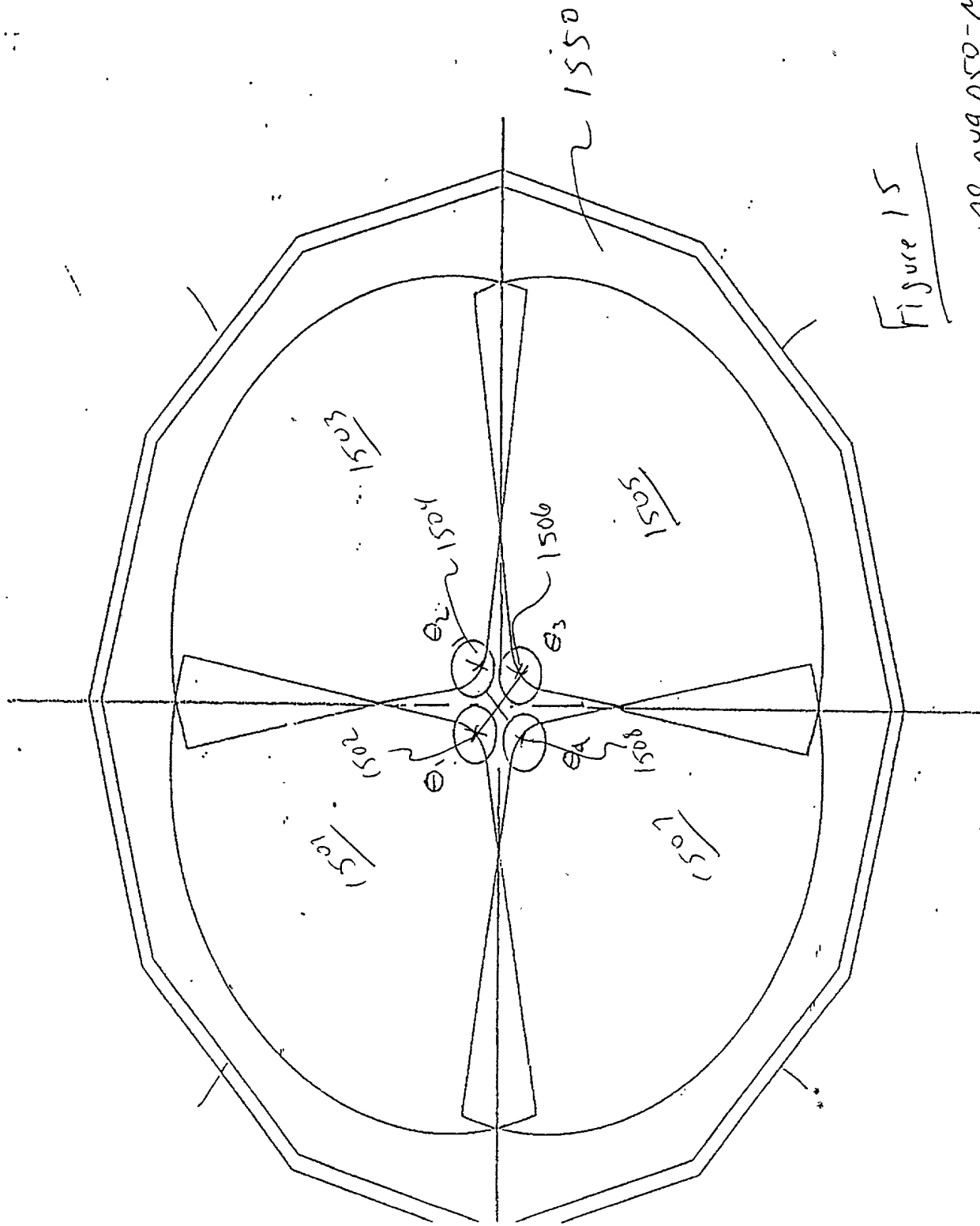


Figure 15

99-049,050-MJ S

DECLARATION FOR PATENT APPLICATION

As a below named inventor, I hereby declare that my residence, post office address, and citizenship are as stated below next to my name.

I believe I am the original, first and sole inventor of the subject matter which is claimed and for which a patent is sought on the invention entitled: "DUAL CONCENTRIC ROBOTIC HIGH PERFORMANCE AUTOMATED TAPE CARTRIDGE SYSTEM", the specification of which (check one):

[+] is attached hereto
[] was filed on _____ as Application Serial No. _____ and was amended on _____ (if applicable).

I hereby state that I have reviewed and understand the contents of the above-identified specification, including the claims as amended by any amendment referred to above.

I acknowledge the duty to disclose information which is material to the examination of this application in accordance with Title 37, Code of Federal Regulations, ' 1.56(a).

I hereby claim foreign priority benefits under Title 35, United States Code, ' 119, of any foreign application(s) for patent or inventor's certificate listed below and also identified below any foreign application for patent or inventor's certificate having a filing date before that of the application which priority is claimed:

Prior Foreign Application(s):			Priority Claimed?	
(Number)	(Country)	(Day/Month/Year Filed)	[] Yes	[] No
(Number)	(Country)	(Day/Month/Year Filed)	[] Yes	[] No

I hereby claim the benefit under Title 35, United States Code, ' 120, of any United States application(s) listed below and insofar as the subject matter of each of the claims of this application is not disclosed in the prior United States application in the manner provided by the first paragraph of Title 35, United States Code, ' 112, I acknowledge the duty to disclose material information as defined in Title 37, Code of Federal Regulations, ' 1.56(a), which occurred between the filing date of the prior application and the national or PCT international filing date of this application:

(Application Serial No.)	(Filing Date)	(Status: Patented, Pending, Abandoned)
(Application Serial No.)	(Filing Date)	(Status: Patented, Pending, Abandoned)

